

In the Claims:

Please amend the claims as follows:

1. (currently amended) A wrist unit (6), intended to be connected to a robot arm in an industrial robot, ~~wherein~~ the wrist unit ~~comprises~~ comprising:

a wrist housing (7),

a wrist part/tilt (8, 33) pivotally journalled in the wrist housing (7) for rotation about a fifth axis of rotation (E), and

a turn disc (9) rotatably journalled in the wrist part/the tilt (8, 33) for rotation about a sixth axis of rotation (F), wherein the sixth axis of rotation (F) is configured to cross the fifth axis of rotation (E), ~~the wrist housing (7) further comprising~~

a first transmission (10) configured to transmit rotation about the fifth axis of rotation (E) to the wrist part/the tilt (8, 33), and

a second transmission (11) configured to transmit rotation about the sixth axis of rotation (F) to the turn disc (9), ~~characterized in that~~ wherein the second transmission (11) comprises a drive-shaft tube arranged symmetrically along the symmetry axis (G) of the wrist housing, the drive-shaft tube (12) is configured to form a continuous channel (14), the channel (14) is configured to receive and accommodate continuous cabling.

2. (currently amended) A The wrist unit according to claim 1, ~~wherein~~ further comprising:

at least one drive means (30, 31) is arranged for driving one of the transmission (10, 11).

3. (currently amended) A robot arm comprising a module in the form of a wrist unit according to claim 1 ~~or~~ 2.

4. (currently amended) A The wrist unit according to ~~any of the preceding claims~~ claim 1, wherein the wrist part/the tilt (8) is journalled in double-sided bearings.

5. (currently amended) A The wrist unit according to ~~any of claims 1-3~~ claim 1, wherein the wrist part/the tilt (33) is journalled in a single-sided bearing.

6. (currently amended) An industrial robot, comprising:
a control system and
a manipulator ~~which includes~~ comprising a robot arm (5) and a wrist unit (6), arranged on the robot arm, ~~according to claim 1~~, said wrist unit comprising a wrist housing (7) arranged for rotation about a fourth axis of rotation (D), a wrist part/tilt (8, 33) pivotally journalled in the wrist housing (7) for rotation about a fifth axis of rotation (E), and a turn disc (9) rotatably journalled in the wrist part/the tilt (8, 33) for rotation about a sixth axis of rotation (F), wherein the sixth axis of rotation (F) is configured to intersect the fifth axis of rotation (E), the wrist housing (7) further comprising a first transmission (10) configured to transmit rotation from a first drive means (30) to the tilt (8, 33) for rotation about the fifth axis of rotation (E), and a second transmission (11) configured to transmit rotation from a second drive means (31) to the turn disc (9) for rotation about the sixth axis of rotation (F), ~~characterized in that~~ wherein the first transmission (11) comprises a drive-shaft tube (12) arranged symmetrically along the fourth axis

of rotation (~~D~~), the drive-shaft tube (~~12~~) is configured to form a continuous channel (~~14~~), and ~~that wherein~~ cabling (~~29~~) is arranged drawn through the channel (~~14~~), through the wrist part/the tilt (~~8, 33~~) and is secured to the turn disc that at least one section of the cabling (~~14a~~) is radially fixed to the second drive-shaft tube (~~12~~).

7. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the robot arm comprises at least one drive means (~~30, 31~~).

8. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the drive means (~~30, 31~~) are arranged inside the robot arm (~~5~~).

9. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the drive means (~~30, 31~~) are arranged on the robot arm (~~5~~).

10. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the wrist unit (~~6~~) comprises at least one drive means (~~30, 31~~).

11. (currently amended) A method in an industrial robot (~~1~~) with a control system and a manipulator comprising a robot arm (~~5~~) and a wrist unit (~~6~~), arranged on the robot arm, said wrist unit comprising a wrist housing (~~7~~) arranged for rotation about a fourth axis of rotation (~~D~~), a wrist part/tilt (~~8, 33~~) pivotally journalled in the wrist housing (~~7~~) for rotation about a fifth axis of rotation (~~E~~), and a turn disc (~~9~~) rotatably journalled on the wrist part/the tilt (~~8, 33~~) for rotation about a sixth axis of rotation (~~F~~), wherein the sixth axis of rotation (~~F~~) is configured to cross the

fifth axis of rotation (E), the wrist housing (7) further comprising a first transmission (10) configured to transmit rotation from a first drive means (30) to the tilt (8) for rotation about the fifth axis of rotation (E), and a second transmission (11) configured to transmit rotation from a second drive means (31) to the turn disc (9) for rotation about the sixth axis of rotation (F), wherein the control system (4) controls the first (30) and second (31) drive units, ~~characterized in that the method comprising:~~

bringing the control system ~~is brought~~ to control the first (30) and second drive units such that the gear ratio between a drive-shaft tube included in the first transmission (10), and the turn disc (9) is 1:1.